

IN THE CLAIMS:

Claim 1 (currently amended): A method for identifying an object image that uses a density difference between a background image and an object image in a picture, said method comprising the steps of:

utilizing a method of obtaining a normal vector of the outline portion of an object image: by arranging points p at equal intervals on a picture, and for each respective point p, performing a fundamental wave Fourier transformation for each pixel value on the circumference of the circle which center is point p, and handling a phase obtained from said fundamental wave Fourier transformation as the normal vector of the outline portion of an object image;

arranging a Standard Object image on a picture in which an arrangement point, which is an arbitrary point on said picture that shows a background image, is used as a reference point;

determining a normal vector group on outline portions of said Standard Object image based upon density difference in said background image and said Standard Object image;

determining an angle information of respective normal vectors and determining a position information from said arrangement point to said respective normal vectors of said normal vector group;

storing said position information and angle information as standard data for said arrangement point;

determining, for a picture that shows an object image to be recognized, a normal vector group on outline portions of said object image based upon density difference in said object image and a background image;

determining a plurality of Answer point groups, that correspond to said arrangement points, from said normal vector group based upon said standard data; and

evaluating a focus point region formed by said Answer point group.

Claim 2 (currently amended): The method for identifying an object image according to Claim 1, wherein:

said Standard Object image is divided into two or more parts, and the same number of standard data is formed for each divided Standard Object image;

an Answer point group is determined for each one of said standard data for the object image to be recognized, and [[MAP]] a plurality of screens in which said Answer point group are determined for every standard data are formed for the same number as said divided Standard Object image; and

said respective [[MAP]] plurality of screens are combined into an evaluation screen, and a focus point region formed by Answer point groups of said evaluation screen is evaluated.

Claim 3 (currently amended): The method for identifying an object image according to Claim 1 or Claim 2, wherein:

determining normal vector of background image and storing information of said normal vector group originating from said background image; and

~~wherein~~ of said normal vector groups obtained from said picture that shows said Object image to be recognized, all of said normal vectors in vector groups which ~~vector direction is unchangeable for a predetermined period of time are considered as being~~ originated from said background image; and ~~all of said normal vector groups, which are unchangeable for a long period of time,~~ are removed, and said Answer point group is determined from remaining normal vector groups.

Claim 4 (cancelled).

Claim 5 (cancelled).